

I Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

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1. (Previously amended) A three-dimensional imaging system for acquiring a succession of two-dimensional images of a target volume represented by an array of pixels and transforming the succession of two-dimensional images directly into a three dimensional image, the system comprising:

scanning means to: (i) scan the target volume using an angular scanning technique, and (ii) generate a succession of digitized two-dimensional images thereof representing cross-sections of the target volume on a plurality of planes spaced around an axis of rotation of the scanning means;

memory means storing the succession of digitized two-dimensional images and a data set, the data set comprising: (i) calibration parameters defining the geometric relationship between successive digitized two-dimensional images; and (ii) acquisition parameters defining the geometric and orientational relationship between successive digitized two-dimensional images; and

transformation means responsive to user selection of a three-dimensional image surface to be displayed, said transformation means receiving the digitized two-dimensional images and the data set, representing the three-dimensional image and transforming only image data within the received two-dimensional images that is necessary to view the selected three-dimensional image surface.

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2. (Original) An imaging system as defined in claim 1, wherein the angular scanning technique is an axial scanning technique.
3. (Original) An imaging system as defined in claim 1, wherein the angular scanning technique is a fan scanning technique.
4. (Previously amended) An imaging system as defined in claim 1, wherein the data set includes data defining:
- (i) an address pointer defining the address of the location in the computer memory in which the acquired digitized two-dimensional image data starts
 - (ii) the horizontal and vertical voxel sizes of the acquired images;
 - (iii) the location of the axis of rotation of a transducer with respect to each of the succession of images;
 - (iv) the width and height (i.e. x and y) of each acquired image and the total number of acquired images;
 - (v) the relative orientation of each acquired image to the transducer actuating assembly;
 - (vi) the angular separation of each acquired image; and
 - (vii) the total angle of acquisition.
5. (Original) An imaging system as defined in claim 2, wherein the data set further includes data defining:
- (viii) the degree of out-of-plane tilt of the transducer;
 - (ix) the degree of out-of-plane displacement; and
 - (x) the degree of in-plane tilt.

6. (Previously amended) An imaging system as defined in claim 1, wherein the calibration parameters comprise (i) the horizontal and vertical voxel sizes of the acquired images; and (ii) the location of the axis of rotation of the transducer with respect to each of the succession of images.

7. (Original) An imaging system as defined in claim 6, wherein the calibration parameters further comprise (iii) the degree of out-of-plane tilt of the transducer; (iv) the degree of out-of-plane displacement; and (v) the degree of in-plane tilt.

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8. (Original) An imaging system as defined in claim 1, wherein the acquisition parameters comprise (i) the width and height (i.e. x and y) of each acquired image and the total number of acquired images; (ii) the relative orientation of each acquired image to the transducer actuating assembly; (iii) the angular separation of each acquired image; and (iv) the total angle of acquisition.

9. (Original) An imaging system as defined in claim 4, wherein item (iv) comprises the number of pixels along the x and y axis of each two-dimensional image and the total number of two-dimensional images taken.

10.(Original) An imaging system as defined in claim 4, wherein item (ii) comprises the physical distance between the centres of adjacent pixels in both the x and the y directions in each two-dimensional image.

11.(Original) An imaging system as defined in claim 1, wherein the transformation means includes a means to generate a reverse map.

12.(Previously amended) An imaging system as defined in claim 11, wherein the reverse map encloses edges of each two-dimensional image

and is oriented in a plane orthogonal to the planes of the two-dimensional images.

13.(Previously amended) A method of transforming a succession of two-dimensional images of a target volume represented by an array of pixels directly into a three dimensional image, the method comprising the steps of:

scanning the target volume along an angular scanning path:

generating a succession of digitized two-dimensional images representing cross-sections of the target volume on a plurality of planes spaced around an axis of rotation of the scanning means;

storing the succession of digitized two-dimensional images in a memory;

storing a data set in the memory, the data set comprising (i) calibration parameters defining the geometric relationship between successive digitized two-dimensional images; and (ii) acquisition parameters defining the geometric and orientational relationship between successive digitized two-dimensional images;

accessing the digitized two-dimensional images and a calibration file; and transforming the digitized two-dimensional and the data set representing the three-dimensional image and transforming only image data within the received two-dimensional images that is necessary to view at least a portion of the selected three-dimensional image surface.